

PRECISE POSITIONING OF MEDIA

BACKGROUND

5 1. Field of the Invention

The present invention relates in general to measurement systems for media mounted on a spindle or media spooled onto a spindle. More specifically, the invention relates to storage media such as spinning magnetic hard disks, optical
10 storage disks, tape drives and other overcoats on top of, e.g., optical filters, lenses or mirrors and especially to the positioning of magnetic hard disks mounted on a spindle. Still more specifically, the invention pertains to
15 positioning such disks in a test system.

2. Description of Related Art

Magnetic disks are data carriers with a very large storage
20 capacity. 30 GB can be stored on a magnetic disk of about 95 mm in diameter.

In addition to the high storage density the disks must have precise magnetic, mechanical as well as certain
25 tribological characteristics. When later used in practice, the disks rotate at approx. 7200 revolutions per minute and more. This means that the outer edge of the disk reaches a speed of higher than 100 km/h during which the write/read element is at less than one twenty-thousandths of a
30 millimeter (< 50 nm) away from the disk surface.

These quality requirements can only be achieved through the greatest precision in manufacture and statistical process controls.

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To achieve high storage densities, a thin film head is used for recording and reading data from modern high-capacity magnetic disks.

10 The surfaces of such disks and the surfaces of other materials like optical filters, lenses or mirrors may contain features in the sub-micrometer range, such as contamination, sputtering defects, impurities, presputter contamination, scratches, delamination defects, data
15 defects, servo defects, etc. Especially, defects which are distributed across the surface of these thin film disks can significantly influence the production yield of disk drives. These defects can be caused by a local change in the topography or the magnetic structure. In the read back
20 signal such defects lead to so-called "thermal asperities" or "missing pulses".

Even sub-micrometer defects of a few nanometers height can lead to disk failure or scrap in production. The exact
25 characterization of these defects is therefore extremely important for today's magnetic disks.

In this, it is particularly important to create a correlation between the sub-micrometer defects, e.g., the
30 topography of the magnetic disk or its magnetic structure

and the resulting disturbances in read signals or other test signals like piezoelectric response, acoustic emission response, laser doppler response, optical response, etc. This is a basis for a general analysis of defects on the storage medium.

To detect errors in the test signal, spin stand testers are used. In particular, for detecting topographic defects, glide testers or optical disk analyzers are used and for magnetic disk characterization, magnetic spin stand testers are utilized. However, the test signals of the above mentioned test systems allow only a limited interpretation of the defects based on read signal analysis, whereas other or additional test techniques allow a further investigation of defect areas or other areas of interest. Using several characterization methods leads to a complementary analysis of defects. Using a combination of these techniques permits to optimize manufacturing parameters and therefore yield to better hard disk drive (HDD) quality.

A characterization with regard to topography and the magnetic characteristics can, however, be carried out using an atomic force microscope (AFM) or magnetic force microscope (MFM). The maximum range which can be recorded with such devices is typically limited to an area of 100 μm x 100 μm . However, an analysis of an area of 20 μm x 20 μm or below is more convenient in terms of defect characterization precision.

A disk failure analysis is carried out in the following typical way: The storage medium having a potential defect is mounted to the spin stand tester and fixed with the spindle, e.g., by a clamp mechanism. Defects are identified at high rotational speed as a particular response of the sensor (e.g., magnetoresistive element, piezoelectric element, etc.). The position of identified defects is given precisely by a radius r_i and an angular position ϕ_i in respect to reference values (ϕ_0, r_0) . For example the defect angle ϕ_i is counted from a predefined reference position ϕ_0 given by the spindle drive, spindle electronics or spindle software (e.g., a pen marker or a TTL index signal) and the alignment of the sensor against a magnetic disk or a reference caliper. r_i is counted from the disk edge or a predefined written track in the magnetic storage media.

For further analysis, the storage medium is removed from the spin stand tester and inserted into the complementary analysis tool (CAT). However, the defect co-ordinate system is lost in this removal and reinsertion into the CAT. The offset induced by the removal and reinsertion to the new analysis tool can be up to 700 μm , which is not suitable to perform an automated measurement, because further searches and/or individual searches are still necessary. A CAT tool is for example a SEM, SIMS, EDX, AFM or even a defect marking tool.

In order to overcome this disadvantage, a combination of a MAG tester (magnetic tester, spin tester) and an AFM has

been proposed in the state of the art (US-A-6,297,630) which is able to directly and quickly detect and characterize sub-micrometer defects on the surface of magnetic disks.

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In Research Disclosure n428, vol. 12, 1999, page 1676, a combination of a Glide Height Tester (GHT) or Acoustic Emission Tester (AET) and an AFM is disclosed. When using a GHT, a specific measuring head flies over the rotating thin
10 film disk. The head is not able either to read or write. However, in case it strikes an elevation on the surface of the disk, a piezoelectric signal is generated due to the hit of the head with this asperity. The test signal is correlated to the height of the elevation. The information
15 of the height and size of defects which is determined via the GHT sometimes depends on its calibration and is sometimes not sufficient for nanometer analysis and quality control. The GHT allows a generation of a defect map (r_i, ϕ_i) . The proposed combination uses a similar co-
20 ordinate system between the GHT and the CAT. Based on the defect co-ordinates determined by the GHT, the CATs are positioned at the defects for further analysis. Thus, the topography of the disk defects or other data can be measured directly.

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As can be taken from the above, measurements on hard disks, especially on a nanoscale, are performed while the disk is located on a spindle. As a consequence that the disk is not removed from the test unit, the co-ordinate system which is

defined by the spindle, the test setup and the test software is not lost.

After having generated a defect map by measuring defects on
5 the rotating disk, each single defect now can be selected
and is then specifically positioned with respect to the CAT
and measured. This, however, has to be done while the disk
is not rotating at, e.g., 7200 RPM, i.e., the disk being
stationary or rotating only very slowly. For the
10 positioning of defects for CAT measurement the disk and/or
the CAT have to be positioned precisely relative to the
measurement position. The angular position can be changed
by rotating the spindle where the disk is clamped, e.g., by
a stepper motor.

15 A specific sector of the storage medium, i.e., the magnetic
disk, can be positioned at any angle at very high precision
by counting encoder signals (TTL signals) in dependence of
the angle relative to a zero position. This is shown in
20 Fig. 1. These pulses may come from a commercial spindle or
are generated by additional hardware or software. When the
target in angular position (TAP in Fig. 1) is reached, the
rotation has to be stopped by a break mechanism or the
spindle rotation has to be slowed down by a defined
25 procedure (e.g., a ramp which reduces the spindle rotation
velocity). For example the stepper motor movement can be
halted or can be ramped down. The ramp down of the stepper
motor is associated with a ramp down time which leads to a
spindle angle offset (SAO) relative to the initial angular
30 position (TAP). This spindle offset can be compensated by a

new $TAP_{new} = TAP - SAO$. However different spindle rotation velocity and stepper motor parameters might require different SAOs. SAO can be significantly high owing to the computer control time and computer communication time with the stepper motor. In particular, a hardware dependent behavior was observed. In contrast to ramp down, the abrupt stopping causes post oscillations of the spindle resulting in angular inaccuracies.

Typically, a spindle is controlled and operated by using encoder signals (typically 2) and an index signal (one index signal for one turn). These signals (e.g., TTL signals) are used to define the rotational speed and rotational direction. The number of encoder signals is well-defined for one turn. The number of encoder signals, in respect to the index signal, defines an angular position. When the spindle rotates, starting at the index signal, a counter may count only the rising edge (transition from 0V to 5V) of the TTL encoder signal.

In the following, an example is given that is illustrated by Fig. 1. It is assumed that there are 1000 encoder TTL signals per rotation of the spindle. In case a sector of interest of the storage medium is to be positioned at an angle ϕ of 115.95 degrees relative to a zero position (for investigating a defect on the magnetic disk located at exactly this position), the spindle has to be rotated by $115.95/360 \times 1000$ encoder signals forward, in other words, by 322 steps (P_{In}) and a fraction of 0.83 steps (P_{Fr}).

The number of index pulses can be counted very precisely by a software or hardware counter. However, stopping a moving mass like a spindle at a certain position, e.g., in the above example, at 322 index pulses, causes a certain
5 oscillation when it is stopped "abruptly". It has to be mentioned that these oscillations do not lead to exactly the same end positions of the spindle in every case, depending on spindle velocity and spindle mass, spindle mass distribution and spindle friction parameters. An
10 example of such oscillations is given in Fig. 1.

Fig. 1 shows the oscillations being represented by a continuous line. TAP is the angle position of the medium where the spindle is braked (after the 322th encoder pulse) and FA is the final angle position of the medium after the
15 spindle has come to a complete stop. It can be seen that the counter adds 5 encoder pulses (1 to 5 in Fig. 1) during the oscillation. It has to be mentioned that in this example only TTL signals from 0 to 5V (rising edge) are
20 counted. However, these edges from the signal appear in both rotational directions, in particular during the swing back of the spindle. Accordingly, any positioning which counts such pulses owing to oscillation of the spindle is not very exact and leads to severe errors in positioning.
25 This, in turn, may lead to miss-positioning of defects for the CAT and as a consequence, to an analysis of an area which is not representative for the failure. In our example the miss-counting of only 1 TTL signal causes a positioning error of 50-100 μm .

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Post oscillations of the spindle can be excluded by using damping parameters of the spindle in such a way that an aperiodic behavior is adjusted. This is known from literature and is used in numerous measuring instruments.

5 However, adjusting an exact aperiodic behavior requires additional hardware for damping the spindle movement. During the spin tests at higher rotational velocities this hardware must be disabled or withdrawn. Furthermore, the damping parameters and behavior have to be well adjusted to

10 achieve the aperiodic condition. If the aperiodic condition is not met exactly, then either the spindle swings back resulting in additional unwanted index pulses or the spindle slowly rotates towards its final position (creep-condition). Even a very small swing back can lead to an

15 additional counting of a TTL signal. In principle, the creep- case can be used to exclude a swing-back. As explained later, the stepper motor is used for fine positioning of the spindle. In case of the creep-case-condition being adjusted and the final position of the

20 spindle angle (i.e., the position of the defect or the like to be analyzed) being reached, the spindle rotates further slowly away from this final position. Thus, adjusting the creep condition cannot be used for fine positioning.

25 Both cases can be adjusted by adding a damping device (e.g., eddy current brake) which effect is described via a velocity dependent term. Its proportional factor is given by the damping factor β . Friction forces between two bodies are basically not velocity dependent and therefore do not

30 contribute to this term. It is known from literature that a

movement (e.g., a pointer in a measurement device) which is dominated by friction term leads to different end portions than a movement not dominated by the friction term. Therefore, a friction term is not wanted in measurement applications.

To solve the positioning problem, it is possible to define non- identical index pulses or a continuous signal in dependence of the angle (e.g., the height of a signal) what, however, would require more electronic effort to read out each of the pulses separately. This would lead to additional hard- and software to be installed.

In addition, it would be possible to differentiate a movement of the spindle backward or forward to separate counts. However, in this case, more soft- and hardware is required as well.

Furthermore, it would be possible to reduce the rotational positioning speed so that the above described effect of post oscillations is minimized or does not occur. This, however, causes a longer rotational positioning time which is not desired. Only a positioning time of a few seconds is tolerable for most applications.

Thus, there is a need to provide a device and a method to stop the spindle in such a way that an exact positioning of the spindle is possible, by simultaneously keeping a small overall positioning time.

SUMMARY OF THE INVENTION

It is therefore the object of the invention to provide a device, a method and a counting technique that allows for
5 the precise positioning of a medium positioned on a spindle.

It is a further object of the present invention to provide such a device whereby no swing back oscillation of the
10 spindle occurs.

It is another object of the present invention to provide such a device for a medium showing sub-micron features on its surface, whereby said features essentially determine
15 said medium's performance.

It is still another object of the invention to provide such a device and method that can be easily implemented and adjusted and is not very cost-consuming. In addition the
20 method shall not alter spin test performance or impact spin test warranty.

These and other objects and advantages are achieved by the apparatus (device) and method disclosed in the claims.
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Advantageous embodiments of the invention are disclosed in the dependent claims.

BRIEF DESCRIPTION OF THE DRAWINGS

The invention will in the following be described in more detail in conjunction with the drawings, in which

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Fig. 1 schematically shows the oscillations of a spindle occurring when braking a magnetic disk mounted on this spindle;

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Fig. 2A is a top view of the spring bar device according to the invention;

Fig. 2B schematically shows the forces acting on the spindle;

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Fig. 3A is a side view of the spring bar device of Fig. 2A;

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Fig. 3B schematically shows the relation between the stepper motor turning axis and the rotational axis of the friction wheel of the stepper motor;

Fig. 4 shows spindle behavior using the adjusted spring bar device;

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Fig. 5 shows the typical case of the adjusted friction force terms of the spring bar device; and

Fig. 6 shows the typical case for two possible adjustments of the spring bar device to exclude a swing-back and spindle oscillations.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENT

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Though the invention may be used for the precise positioning of other media than magnetic hard disks, e.g., for optical filters, lenses or mirrors - detecting sub-micron features like defects, etc. on such surfaces by means of respective common high quality test methods, and analyzing the features found with a CAT is also important - the precise positioning method of the present invention will, in the following, only be described with respect to a spinning magnetic disk.

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The underlying idea is to position magnetic disks precisely by using a combination of a spindle friction element to adjust static and dynamic friction and a respective counting technique for exactly moving the spindle to its exact position.

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As has been already mentioned above, abruptly stopping the spindle leads to oscillations of the spindle causing an inexact positioning of the magnetic disk, and thus an exact measurement of the defect or the like on the disk is not possible. Accordingly, it is necessary to brake the spindle in such a way that no oscillation (swing back) of the spindle occurs.

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As will be shown, this can be done using an additional friction element, which prevents the oscillation behavior shown in Fig. 1. Together with counting the encoder signals, this allows to precisely position a medium.

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Friction forces act between two bodies in contact which are moved against each other. The friction force is parallel to their contact area and is directed to the opposite side of the body's movement. The friction force F_f is smaller than the normal force F_N (Fig. 2B) and is described using the friction coefficient μ by $F_{SB} = \mu F_N$. Two different friction modes exist: First, the static friction which takes place when a body is not moving against the other body. This static friction has to be overcome when this body is to be moved. The parameter describing the static friction is μ_0 . Second, when two bodies that are in contact move against each other, the sliding friction takes place. The sliding friction μ_g is smaller than the static friction ($\mu_0 > \mu_g$).

20 Figs. 2 and 3 schematically show an example of the apparatus according to the invention. A magnetic disk 6 to be investigated is mounted on a spindle hub 4. A stepper motor 10 is mounted next to the hub 4. The stepper motor 10 consists of a rotational axis 22 which can be rotated very precisely step by step via an electronic controller unit. At the rotational axis 22 a turning or friction wheel 14 is fixed for transformation of the rotation to another element (e.g. the spindle 4). The friction wheel 14 can be made of metal or plastic. The wheel can be coated by a specific coating 16 for friction wheels (teflon) or an elastic ring

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(rubber) can be attached. This coating is used to enable a good contact with the spindle. In particular, a material is selected which does not show a strong hysteresis when the stepper motor is rotated clock- or counter-clockwise.

5 Furthermore, the material of the coating is selected such that it does not relax strongly as a function of time.

Two positions of the stepper motor 10 arrangement can be selected. One position is for locating the friction wheel 10 14 to be not in contact with the spindle 4 (position "out"). This is used when the spindle stand test is performed. In the second position (position "in"), the friction wheel 14 is in defined contact with the spindle 4. This position is used during the positioning procedure of 15 the CAT. Both positions can be adjusted by using a mechanical switch or relay. The stepper motor 10 can be more precisely approached by using a linear table. This allows a careful adjustment of the pressure used to press the elastic ring or coating 16 against the spindle 4.

20 A bar 2, made, e.g., from a metal like aluminum or the like, or being made of steel coated with teflon to minimize abrasion so that the apparatus may be used within a clean room, is arranged below the magnetic disk 6 near the spindle hub 4. This bar may be formed of a flexible spring 25 that can be pressed against the spindle hub 4 and released again (cf. the grey double arrow in Fig. 2). The movement of the bar is controlled by a relay 8 connected to the bar. It may also be controlled by an air pressure cylinder or 30 the like. The relay 8 is controlled by software. The force

F_N used to press the bar 2 against the spindle hub 4 (cf. Fig. 2B) can be adjusted by means of an adjusting device, e.g., by a screw 12 having a variable stop 18, which allows to increase or decrease the friction force. Instead of
5 using a screw 12, the amount of electrical current of the relay 8 can be used to adjust the force of the bar against the spindle hub 4. A spring balance having a scale or the like may also be used. In general, the force depends on several parameters like the length of the spring, the
10 spring constant, the excursion of the spring, the Young's modulus and the friction coefficient of the materials used.

The friction force of the bar 2 (in the following called F_{SB} , cf: Fig. 2B) can be subdivided into two different
15 portions, namely the sliding friction part (in the following called F_{SlSB}) and the static friction part (in the following called F_{StSB}). When the spindle is static and the stepper motor is started, the static friction has to be overcome. Once the spindle rotates, there is only the
20 sliding friction. According to the present invention, F_{SB} can be used to achieve non-oscillatory braking conditions of the spindle hub 4. This will be described in the following with respect to Fig. 4, thereby using the example given in connection with Fig. 1.

25 Just before starting the actual positioning procedure, i.e., when the CAT is activated, the bar 2 is pressed against the spindle hub 4 with a defined force that can be adjusted by the screw 12 (the adjustment procedure is
30 explained in more detail below). The spindle hub 4 carrying

the magnetic disk 6 under investigation is rotated by the stepper motor 10 counter- clockwise (cf. the bended arrow in Fig. 2) towards its final position, i.e., the position of the defect or the like to be measured ("a" in Fig. 4).

5 When a predefined encoder signal number (in the case shown at TAP = 317, this value depending on the specific apparatus used) is reached (in this case $TAP = P_{In} - x$, where, in this esample, $x = 5$ and $P_{In} = 322$, cf. Fig. 1), the stepper motor is stopped. Due to the mass moment of inertia

10 the spindle 4 rotates further in counter-clockwise direction. However, the elastic ring or coating 16 (Figs. 2, 3) of the stepper motor and the electromagnets inside the stepper motor are acting against such spindle rotation. Therefore the spindle rotation is slowed down ("b" in Fig.

15 4). When most of the rotational energy is dissipated into potential energy of the elastic ring or coating 16 of the stepper motor 10, a specific amount of force F_E occurs which acts on the spindle in the opposite direction to initial spindle rotation, i.e., in the direction of clockwise

20 rotation. This is shown by the turning point "T" in Fig. 4, where the grey line indicates the swing back of the spindle hub 4. The bar 2 pressed against the spindle hub 4 thereby realizes an additional friction element which reduces velocity of this counter-clockwise rotation due to the

25 sliding friction term, F_{S1SB} . However, the friction force of the spring F_{SB} can be adjusted in such a way using F_N , that at the turning point "T", the force of static friction, F_{StSB} , is higher than F_E . As explained before, the static friction has to be overcome until the spindle is rotated.

30 Thus, a swing back of the spindle hub 4 is excluded and the

position of the spindle is stable ("c" in Fig. 4). Since all counter-clockwise directions in part b are counted by the counting technique according to the invention, the actual range of "b" is not critical.

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The actual position of the turning point "T" in the present example is encoder signal 319. Fine positioning to the final defect angle FA (encoder signal 322.83, cf. the example of Fig. 1) is represented by sections "d" to "f" in Fig. 4 and will be described in the following.

As has been described before, there is no oscillation of the spindle hub 4 at the turning point "T", corresponding to a value of 319 encoder steps, i.e., this position is static. However, the exact position of the spindle between encoder signals 319 and 320 is not known since only the rising edges of the pulses are counted. Now the stepper motor 10 is used to turn the spindle stepwise (motor steps MS) in counter-clockwise direction by small angles ϕ ("d" in Fig. 4), i.e., from one encoder signal to the next. Turning the friction wheel of the stepper motor increases the force F_E and in case F_E exceeds F_{StSB} , the spindle will rotate a small angle in the counter-clockwise direction. The precision for fine positioning is increased by a stepper motor having high accuracy, by using a mechanical translation, a friction wheel with a smaller diameter and/or materials having a small difference between the coefficients of the sliding and the static friction.

When the spindle is rotated stepwise, the next encoder signal that is reached in the present example is signal 320. The stepwise rotation is continued until the encoder signal number $P_{In} - 1$ is reached, i.e., encoder signal 321.

5 In the example outlined in section "d" in Fig. 4, 13 MS are necessary to reach encoder signal 321. Then the number of motorsteps MS between this encoder signal and the next one, $N_{P_{In} - (P_{In} - 1)}$, is counted ("e" in Fig. 4). In the example of Fig. 4, a number of $N_{322 - (322 - 1)} = 8$ is obtained. Based on this
10 value the remaining number N_{Fr} of motor steps MS, which are necessary to reach the encoder signal fraction $P_{Fr} = 0.8$ is calculated by using the equation

$$N_{Fr} = \text{int}(P_{Fr} \times N_{In - (In - 1)}),$$

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which in the present example leads to a value of 6. This calculation has the additional advantage that also unwanted influences like, e.g., balance errors of the stepper motor and the like, are excluded.

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Then the spindle is turned further for $N_{Fr} = 6$ MS in counter- clockwise direction ("f" in Fig. 4). Now, the defect angle FA has been reached.

25 This fine positioning method improves angular position accuracy by reading encoder signals only. The positioning resolution is therefore dependent on the number of motorsteps MS between two encoder signals. The number can be increased by a high resolution stepper or dc motor or by
30 a down-transformation. The latter can be realized by a

friction wheel having a small diameter or a turning transformation.

One advantage of this technique is that the friction wheel
5 need not be positioned very exactly with respect to the spindle and therefore different types of motors can be used without changing the software or modifying the counting technique. In particular, it is allowed that the stepper motor turning axis 20 and the rotational axis 22 of the
10 friction wheel being different (i.e., forming an angle α shown in Fig. 3B) This leads to a non-uniform turning of the spindle with a periodicity of 360 deg. The used counting technique measures the distance between encoder signals in terms of motor steps MS at an angle very close
15 to the defect. Here the turning uniformity difference between two adjacent encoder signals can be neglected. Even further non-uniform turning periodicity larger than two encoder signals are allowed and do not influence substantially the positioning accuracy. These changes may
20 come from the shape and mounting of the friction wheel.

The system disclosed here has the advantage that it combines a very fast and exact positioning of the spindle, so that no defects found by means of the spin stand tester
25 can be missed. Consequently, a higher throughput can be achieved and the measuring system can be highly automated to achieve high throughput. The adjustment procedure of the bar at the turning point "T" ($F_{StSB} > F_E$ or $F_{SlSB} > F_E$, respectively) which is pressed against the spindle hub can
30 be realized by the following techniques:

F_E is dependent on the velocity of the spindle and the friction wheel material and friction wheel coating; the higher the velocity, the higher F_E . Therefore, the term F_{StSB} is adjusted for the maximal velocity of the spindle which is determined by the velocity of the stepper motor. The latter is computer controlled and this rotational speed can be adjusted precisely. The next adjustment process is described in the following.

To prevent oscillation of the spindle, the friction force of the spring bar device has to be adjusted to $F_E < F_{SB}$, in that the oscillation of the spindle backwards is excluded. This can be realized by looking at a characteristic or well-defined marker on the disk surface (e.g. artificial defect) or at the spindle (e.g. scales) via an observation tool (e.g. High Speed camera or photo detector). The observation of the characteristics or well-defined marker during the positioning procedure represents the spindle behavior and enables a statement of the oscillation behavior of the spindle, when the spindle is braked by the stepper motor stop.

Fig. 5 schematically depicts an example of an adjustment procedure of the friction force at the bar 2. TAP is the angle position of the medium, where the spindle is stopped and FA represents the final angle position of the spindle, i.e., the angle of the defect to be observed. The grey rectangle indicates a characteristic or well-defined marker on the disk surfaces or at the spindle.

The well-defined marker is monitored via an observation tool, e.g., a High Speed camera or a photo detector. The case shown indicates the spindle positioning behavior, when
5 the friction force is adjusted so that no oscillation backwards occurs. It can be adjusted by a screw 12 at the bar. When the spindle is braked at TAP, it moves without any oscillation towards the final angle position FA. In the example shown in Fig. 5, it is not necessary to adjust one
10 well defined force value. It is only important that a force is adjusted which is higher than F_E .

The adjustment procedure of friction force is performed by changing the friction force until the shown case is
15 performed (Fig. 5).

Even a higher friction force than F_{StSB} can be adjusted by the bar. This leads also to a precise positioning of the spindle. This case is outlined together with the F_{StSB} case
20 in Fig. 6. In contrast to the case where the spindle is stopped at the turning point "T" at a higher friction force, the spindle is stopped before the turning point. This eliminates spindle oscillation and allows a good tolerance in adjusting the spring bar device.

25 The positioning technique can also be used for precise definition of the starting point, in particular the angle between the index or encoder to a reference position of the disk. The technique according to the invention allows a

quick and precise positioning of a medium mounted on the spindle.

5 The following entries are examples of aspects of the invention:

Entry 1. An apparatus for exactly positioning a medium (6) mounted on a spindle (4), said apparatus comprising a device (10) for continuously changing the angular
10 position of said medium with respect to a predefined reference position by rotating said spindle,

characterized in that

15 said apparatus additionally comprises a friction element (2) for braking said spindle at a predetermined position, not allowing a swing back.

Entry 2. The apparatus according to entry 1, wherein said
20 device (10) is a stepper motor.

Entry 3. The apparatus according to entry 1 or 2, wherein said friction element (2) comprises a bar being adapted to be pressed against said spindle (4).
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Entry 4. The apparatus according to entry 3, wherein said bar (2) comprises a flexible spring.

Entry 5. The apparatus according to entry 4, wherein said
30 spring is connected to a relay (8).

Entry 6. The apparatus according to entry 5, wherein said relay (8) is software-controllable.

5 Entry 7. The apparatus according to entry 4, wherein said spring is connected to an air pressure cylinder.

Entry 8. The apparatus according to any one of entries 3 to 7, wherein said bar is made of a metal.

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Entry 9. The apparatus according to entry 8, wherein said metal is aluminum.

Entry 10. The apparatus according to any one of entries 3 to 7, wherein said bar is coated with a low abrasive material.

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Entry 11. The apparatus according to entry 10, wherein said bar is made of teflon coated steel.

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Entry 12. The apparatus according to any one of entries 3 to 11, wherein the force with which the bar is pressed against the spindle is adjustable by means of an adjusting device.

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Entry 13. The apparatus according to entry 12, wherein said adjusting device is a micrometer screw (12).

Entry 14. The apparatus according to any one of the preceding entries, wherein said medium (6) is a spinning medium.

- 5 Entry 15. The apparatus according to entry 14, wherein said spinning medium consists of a magnetic disk.

Entry 16. The apparatus according to any one of entries 1 to 13, wherein said medium (6) is a magnetic tape.

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Entry 17. The apparatus according to any one of entries 1 to 13, wherein said medium (6) is an optical filter, a lense or a mirror.

- 15 Entry 18. A method for exactly positioning a medium (6) mounted on a spindle (4) at a predefined angular position, whereby the angular position of said medium with respect to a predefined reference position is controlled by means of encoder signal pulses and
20 whereby the angular position of said medium can be continuously adjusted by adjusting means (10),

characterized by the steps of

- 25 a) pressing a friction element (2) against said spindle (4) using a predetermined friction force;
- b) rotating said spindle (4) towards said predefined angular position by means of said adjusting means
30 (10);

- 5 c) stopping said spindle (4) at a predefined encoder
signal pulse number P_{In-x} , said predefined encoder
signal pulse number representing an angular position
of said medium (6) close to said predefined angular
position, whereby due to the mass moment of inertia of
said spindle (4) and said predetermined friction force
adjusted in step a) a static position of said spindle
(4) between two encoder signal pulses is achieved;
- 10 d) stepwise rotating said spindle (4) by small angles
until the encoder signal pulse P_{In-1} is reached;
- 15 e) counting the number of steps necessary to move said
spindle (4) to the encoder signal pulse P_{In} next to
said predefined angular position by moving said
spindle (4) to said encoder signal pulse P_N by means of
said adjusting means (10); and
- 20 f) based on said counted number of steps, calculating the
number of steps necessary to move said spindle (4) to
said predefined angular position.

25 Entry 19. The method according to entry 18, wherein said
predetermined friction force is adjusted so that
oscillations of the spindle (4) are excluded when said
spindle (4) is stopped at said predefined encoder
signal pulse number.

Entry 20. The method according to entry 19, wherein said
friction force is adjusted so that the sliding
friction or the static friction of said friction
element (2) is greater than the force acting in the
5 direction opposite to the direction of rotation of
said spindle (4) when said spindle is stopped.